

## PD57/60-x-1076 Hardware Manual

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The PD57/60-1076 is an easy to use PANdrive™ smart stepper motor. The module is controlled via a step and direction interface. One configuration pin selects the current control mode between StealthChop™ for absolute silent motor control and SpreadCycle™ for high speed. A TTL UART interface allows for more advanced configuration, for example of the StallGuard2™ and CoolStep™ features, and permanent parameter storage via TMCL™-IDE.



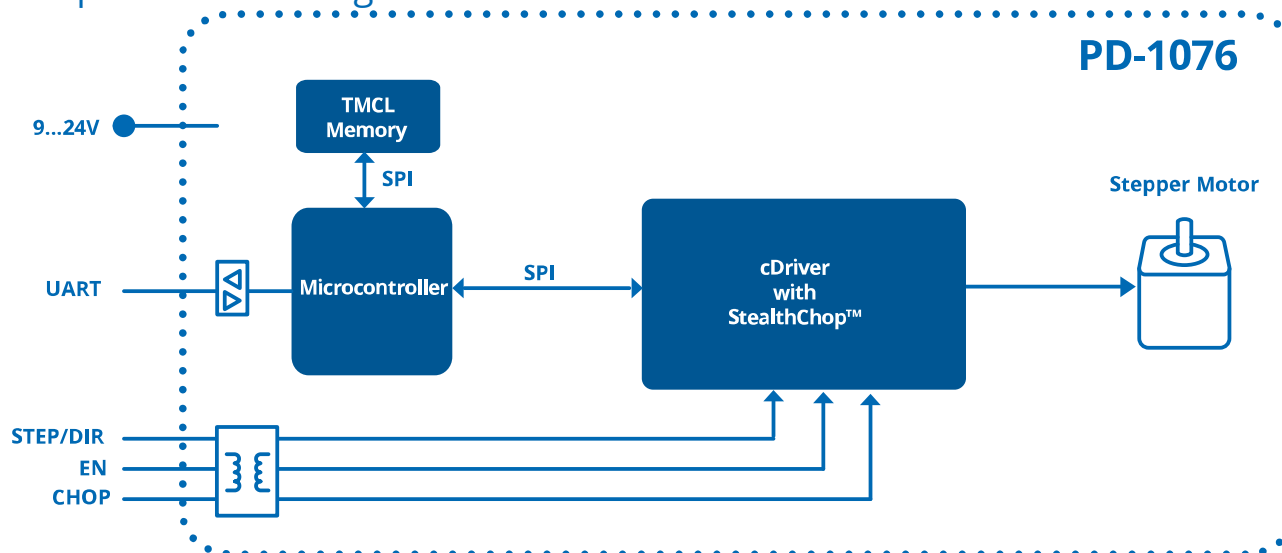
### Features

- Supply Voltage +10...+30V DC
- Up to 3A RMS motor current
- Step and direction interface
- MicroPlyer™ to 256 microsteps
- StealthChop™ silent PWM mode
- SpreadCycle™ smart mixed decay
- StallGuard2™ load detection
- CoolStep™ autom. current scaling
- UART configuration interface

### Applications

- Lab-Automation
- Robotics
- CNC
- Manufacturing
- Factory Automation

### Simplified Block Diagram



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# 1 Features

The PANdrive™ PD57/60-x-1076 is a full mechatronic solution with state of the art feature set. It is highly integrated and offers a convenient handling.

The PD57/60-x-1076 includes a stepper motor and driver electronics. It can be used in many decentralized applications and has been designed for 0.55...3.1 Nm max. holding torque and 24V DC nominal supply voltage. With StealthChop™, the PD57/60-x-1076 offers absolutely silent and smooth motor operation for lower and medium velocities. With SpreadCycle™, the PD57/60-x-1076 offers a high performance current controlled chopper mode for highest velocities with perfect zero crossing performance. With StallGuard2™, a sensorless load detection feature is provided, which is required for using the automatic current scaling feature CoolStep™. The PD57/60-x-1076 can be used with a simple step and direction interface and can be configured using a TTL UART interface.

stallGuard2 and coolStep must be configured via TTL UART interface and are disabled by default.

## 1.1 General Features

### Main Characteristics

- Supply Voltage +10V to +30V DC
- 3A RMS phase current (ca. 4.2A peak phase current)
- Highest micro step resolution, up to 256 micro steps per full step
- MicroPlyer™ microstep interpolator for obtaining increased smoothness of microstepping over a low frequency STEP/DIR interface
- With housing and motor mounted
- Permanent onboard parameter storage
- Simple step & direction mode
- Noiseless StealthChop™ chopper mode for slow to medium velocities
- High performance SpreadCycle™ chopper mode
- High-precision sensorless load measurement with StallGuard2™
- Automatic current scaling algorithm CoolStep™ to save energy and keep your drive cool

### Optically Isolated Inputs

- Step & direction interface with up to 45kHz input frequency
- Enable input to power-on/-off driver H-bridges
- Mode select input to switch between the two chopper modes

### TTL UART Interface

- TTL-level UART interface for parameter configuration
- Interface speed 9600-115200 bps (default 9600 bps)
- TMCL-based protocol for online configuration and permanent parameter settings
- Bootloader for firmware updates

## 1.2 TRINAMIC's Unique Features

### 1.2.1 stealthChop™

stealthChop is an extremely quiet mode of operation for low and medium velocities. It is based on a voltage mode PWM. During standstill and at low velocities, the motor is absolutely noiseless. Thus, stealthChop operated stepper motor applications are very suitable for indoor or home use. The motor operates absolutely free of vibration at low velocities. With stealthChop, the motor current is applied by driving a certain effective voltage into the coil, using a voltage mode PWM. There are no more configurations required except for the regulation of the PWM voltage to yield the motor target current.

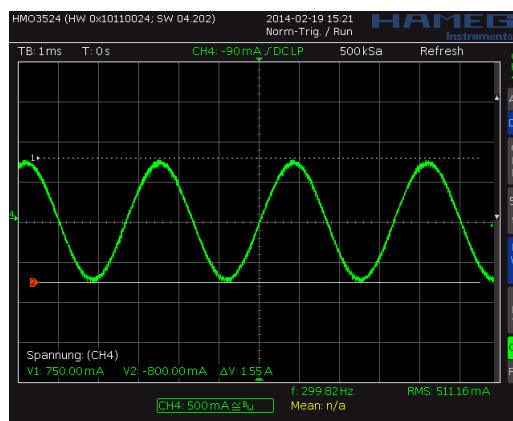


Figure 1: Motor coil sine wave current using stealthChop (measured with current probe)

### 1.2.2 spreadCycle™

The spreadCycle chopper is a high-precision, hysteresis-based, and simple to use chopper mode, which automatically determines the optimum length for the fast-decay phase. Several parameters are available to optimize the chopper to the application. spreadCycle offers optimal zero crossing performance compared to other current controlled chopper algorithms and thereby allows for highest smoothness. The true target current is powered into the motor coils.

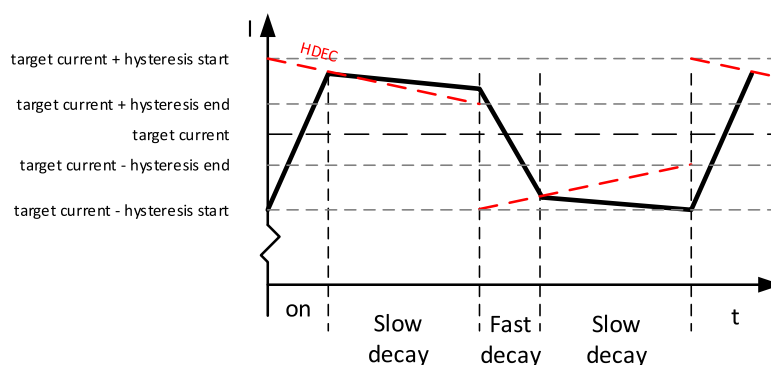


Figure 2: spreadCycle principle

### 1.3 stallGuard2

stallGuard2 is a high-precision sensorless load measurement using the back EMF of the motor coils. It can be used for stall detection as well as other uses at loads below those which stall the motor. The stallGuard2 measurement value changes linearly over a wide range of load, velocity, and current settings. At maximum motor load, the value reaches zero or is near zero. This is the most energy-efficient point of operation for the motor.

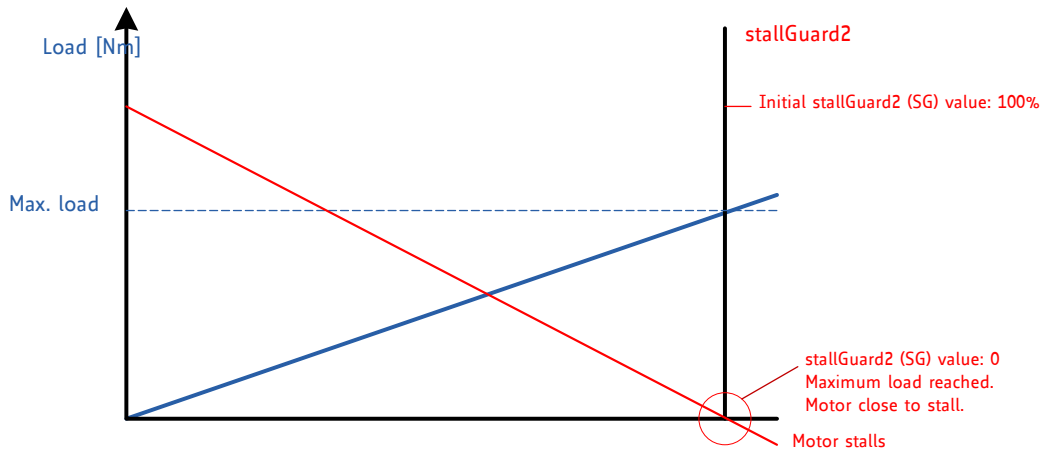


Figure 3: stallGuard2 Load Measurement as a Function of Load

### 1.4 coolStep

coolStep is a load-adaptive automatic current scaling based on the load measurement via stallGuard2. coolStep adapts the required current to the load. Energy consumption can be reduced by as much as 75%. coolStep allows substantial energy savings, especially for motors which see varying loads or operate at a high duty cycle. Because a stepper motor application needs to work with a torque reserve of 30% to 50%, even a constant-load application allows significant energy savings because coolStep automatically enables torque reserve when required. Reducing power consumption keeps the system cooler, increases motor life, and allows for cost reduction.

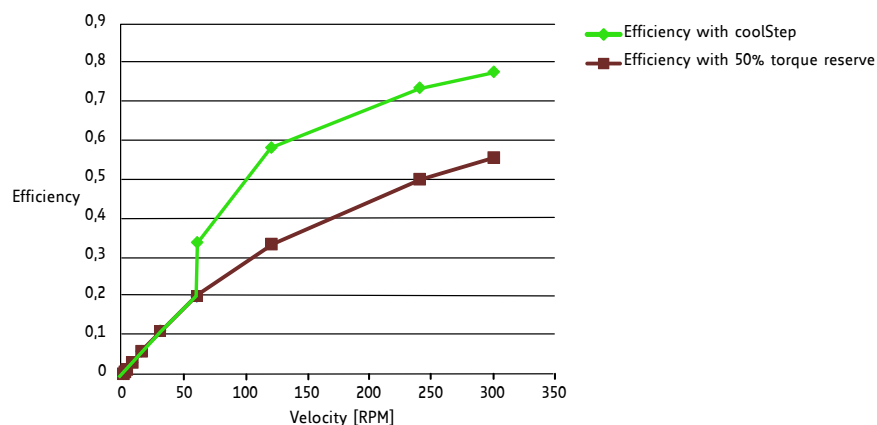


Figure 4: Energy Efficiency Example with coolStep

## 2 Order Codes

| Order Code  | Description   | Size (LxWxH)       |
|-------------|---|--------------------|
| PD57-1-1076 | PANdrive, 0.55Nm, 3A RMS, +24V DC, TTL UART interface, S/D interface, Enable, Mode Select | 60mm x 60mm x 54mm |
| PD57-2-1076 | PANdrive, 1.01Nm, 3A RMS, +24V DC, TTL UART interface, S/D interface, Enable, Mode Select | 60mm x 60mm x 64mm |
| PD60-3-1076 | PANdrive, 2.1Nm, 3A RMS, +24V DC, TTL UART interface, S/D interface, Enable, Mode Select  | 60mm x 60mm x 78mm |
| PD60-4-1076 | PANdrive, 3.1Nm, 3A RMS, +24V DC, TTL UART interface, S/D interface, Enable, Mode Select  | 60mm x 60mm x 99mm |

Table 1: Order codes PANdrives

| Order Code    | Description  |
|---------------|--|
| PD-1076-CABLE | Cable loom for PDxx-1076 and PD57/60-x-1076. Contains: <ul style="list-style-type: none"> <li>• 1x cable loom for motor connector with 4-pin JST EH female connector</li> <li>• 1x cable loom for Power + I/O connector with 9-in JST EH female connector</li> </ul> |

Table 2: Order codes cable loom

### 3 Mechanical and Electrical Interfacing

#### 3.1 PD57/60-x-1076 Dimensions and Weight

The PD57/60-x-1076 includes the TMC1076 stepper motor driver module and a NEMA23 or NEMA24 bipolar stepper motor. Depending on the motor size the length varies.

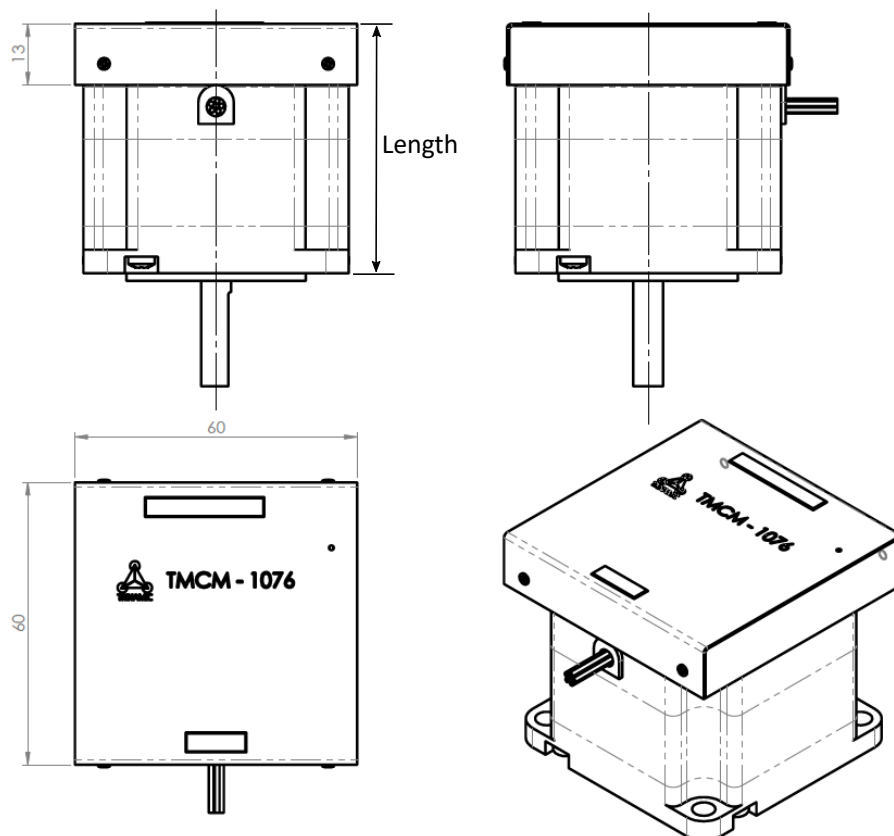


Figure 5: PD57/60-x-1076 mechanical dimensions with motor

| Order Code  | Length in mm | Weight in g |
|-------------|--------------|-------------|
| PD57-1-1076 | 54           | ≈ 520       |
| PD57-2-1076 | 64           | ≈ 720       |
| PD60-3-1076 | 78           | ≈ 1270      |
| PD60-4-1076 | 99           | ≈ 1470      |

Table 3: PD57/60-x-1076 length and weight

### 3.2 PD57/60-x-1076 Motor Parameters

| Specifications                            | Unit              | PD57-1-1076 | PD57-2-1076 | PD60-3-1076 | PD60-4-1076 |
|---|-------------------|-------------|-------------|-------------|-------------|
| Step angle                                | °                 | 1.8         | 1.8         | 1.8         | 1.8         |
| Step angle accuracy                       | %                 | +/-5        | +/-5        | +/-5        | +/-5        |
| Ambient temperature                       | °C                | -20...+50   | -20...+50   | -20...+50   | -20...+50   |
| Max. motor temperature                    | °C                | 80          | 80          | 80          | 80          |
| Shaft radial play (450g load)             | mm                | 0.02        | 0.02        | 0.02        | 0.02        |
| Shaft axial play (450g load)              | mm                | 0.08        | 0.08        | 0.08        | 0.08        |
| Max radial force (20mm from front flange) | N                 | 57          | 57          | 57          | 57          |
| Max axial force                           | N                 | 15          | 15          | 15          | 15          |
| Rated voltage                             | V                 | 2.0         | 2.3         | 3.36        | 4.17        |
| Rated phase current                       | A                 | 2.8         | 2.8         | 2.8         | 2.8         |
| Phase resistance at 20°C                  | Ω                 | 0.7         | 0.83        | 1.2         | 1.5         |
| Phase inductance (typ.)                   | mH                | 1.4         | 2.2         | 4.6         | 6.8         |
| Holding torque                            | Nm                | 0.55        | 1.01        | 2.1         | 3.1         |
| Insulation class                          |                   | B           | B           | B           | B           |
| Rotor inertia                             | g cm <sup>2</sup> | 120         | 275         | 570         | 840         |
| Weight                                    | kg                | 0.45        | 0.65        | 1.2         | 1.4         |

Table 4: NEMA23 / 57mm and NEMA24 / 60mm stepper motor technical data



### 3.3 PD57/60-x-1076 Torque Curves

The following diagrams show the torque vs. speed curves for the PD57-1-1076, the PD57-2-1076, the PD60-3-1076 and the PD60-4-1076 with spreadCycle chopper mode selected, 24V supply voltage and rated motor current (2.8A RMS / 4A peak).

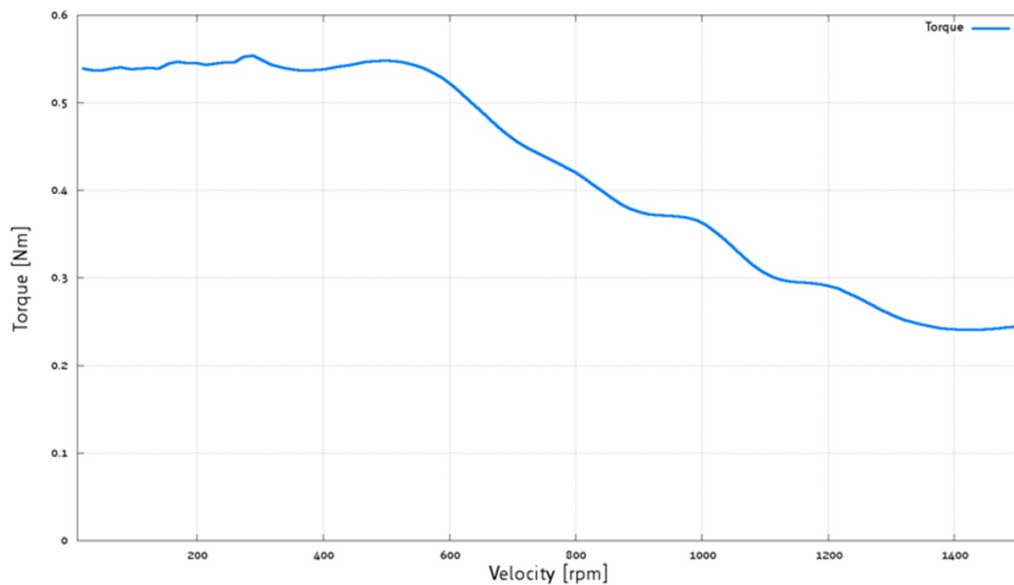


Figure 6: PD57-1-1076 torque vs. velocity 24V / 2.8A, 256 $\mu$ steps

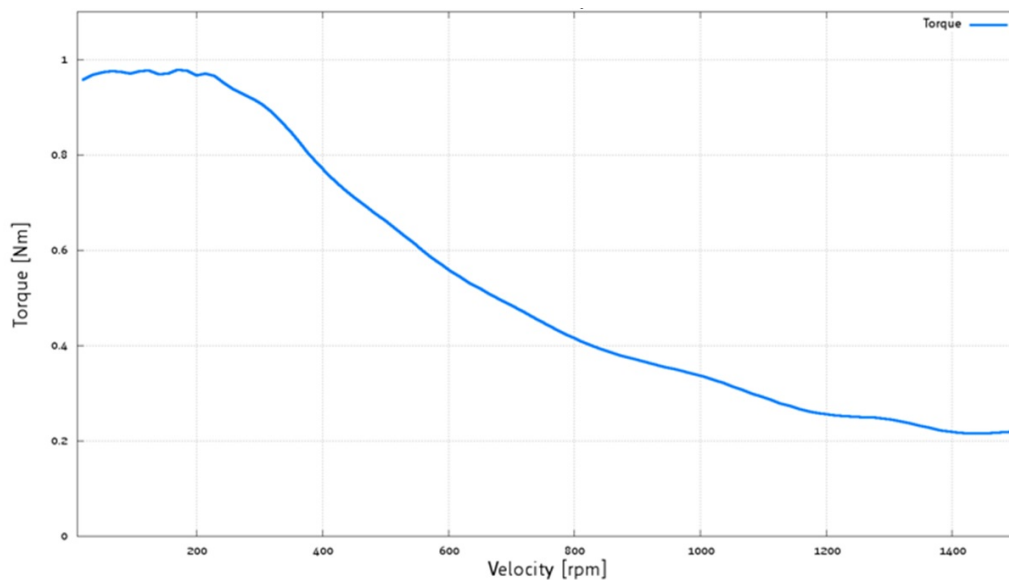


Figure 7: PD57-2-1076 torque vs. velocity 24V / 2.8A, 256 $\mu$ steps

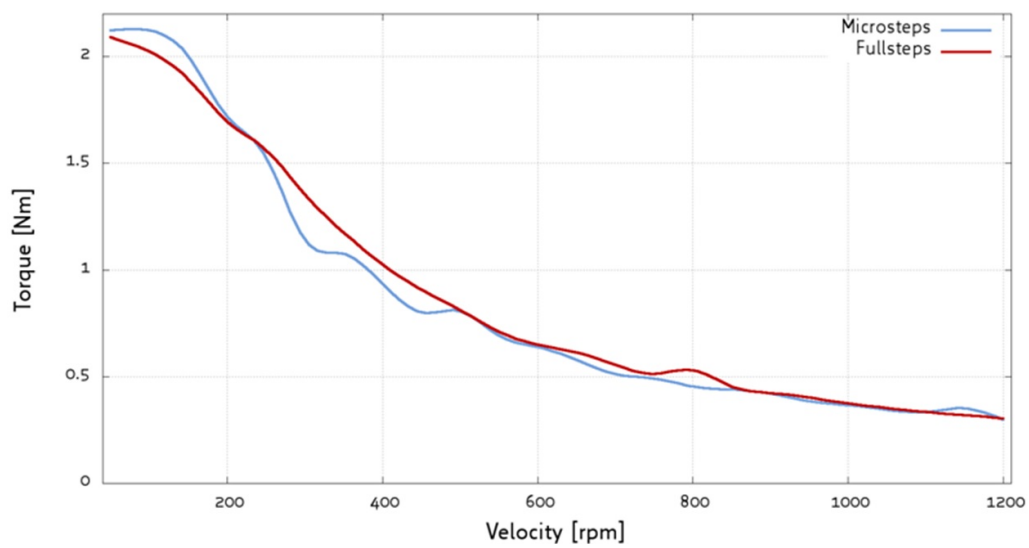


Figure 8: PD60-3-1076 torque vs. velocity 24V / 2.8A, 256 $\mu$ steps

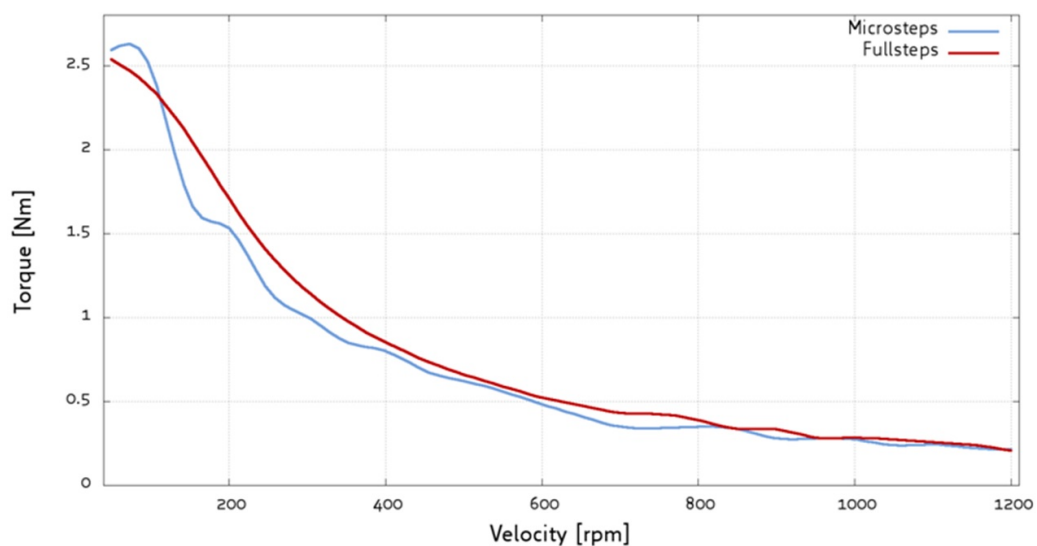


Figure 9: PD60-4-1076 torque vs. velocity 24V / 2.8A, 256 $\mu$ steps

## 4 Connectors and LEDs

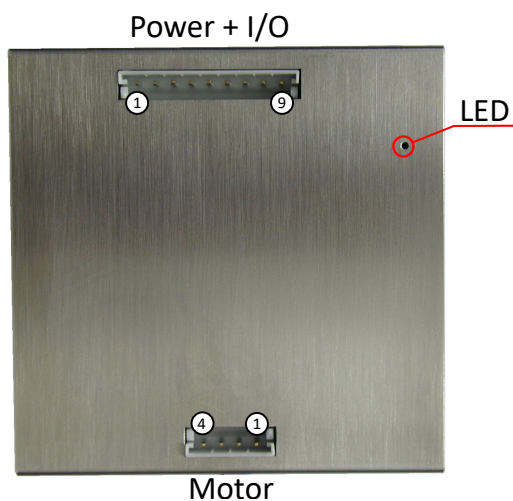


Figure 10: PD57/60-x-1076 connectors

### 4.1 Motor Connector

| Pin no. | Pin name | Description         |
|---------|----------|---------------------|
| 1       | B1       | Motor phase A pin 1 |
| 2       | B2       | Motor phase A pin 2 |
| 3       | A1       | Motor phase B pin 1 |
| 4       | A2       | Motor phase B pin 2 |

Table 5: Motor connector pinning

#### NOTICE

#### Do not connect or disconnect motor during operation!

Motor cable and motor inductivity might lead to voltage spikes when the motor is (dis)connected while energized. These voltage spikes might exceed voltage limits of the driver MOSFETs and might permanently damage them. Therefore, always switch off or disconnect power supply before (dis)connecting the motor.

## 4.2 Power + I/O Connector

| Pin no. | Pin name | Description   |
|---------|----------|---|
| 1       | GND      | Supply ground connection, also used for USB serial converter ground connection  |
| 2       | V+       | Supply voltage ( $V_{DD}$ ) +10V to +30V DC   |
| 3       | DIR      | Optically isolated direction input of S/D interface   |
| 4       | STEP     | Optically isolated step input of S/D interface  |
| 5       | EN       | Optically isolated enable input of motor driver H-bridges   |
| 6       | CHOP     | Optically isolated chopper mode selection input   |
| 7       | COMM     | Opto-coupler common anode or cathode, connect to ground or VCCIO (3.3V to 6V - higher voltages possible with additional external resistors) |
| 8       | RXD      | TTL-level UART receive line, use with USB serial converter TXD line to connect to PC  |
| 9       | TXD      | TTL-level UART transmit line, use with USB serial converter RXD line to connect to PC   |

Table 6: Power + I/O connector pinning

### NOTICE

#### Supply Voltage Buffering / Add External Power Supply Capacitors

A sufficiently buffered power supply or an external electrolyte capacitor connected between V+ and GND is recommended for stable operation. It is recommended to connect an electrolytic capacitor of significant size to the power supply lines next to the PD57/60-x-1076.

Rule of thumb for size of electrolytic capacitor:  $C = 1000 \frac{\mu F}{A} * I_{SUPPLY}$

The PD57/60-x-1076 comes with approximately 40 $\mu$ F of onboard ceramic capacitors.

### NOTICE

#### There is no reverse polarity protection on the supply input!

The module will short any reversed supply voltage and board electronics will get damaged.

### NOTICE

#### Power Up Sequence

The PD57/60-x-1076 must be powered up with disabled driver stage only. Depending on your configuration the EN input should be logically OFF (EN input either open or at the same voltage level as the COMM input).

### 4.3 TTL UART Connection

To connect via the TTL UART interface to a host PC, we suggest using a USB serial converter from TTL-UART (5V) to USB interface.

Communication with the host PC, for example when using TRINAMIC's TMCL-IDE, is done via the Virtual COM port installed by the converter driver.

More information on the TMCL-IDE and the latest release can be found here: [www.trinamic.com](http://www.trinamic.com)

The converter cable must be connected to pins 1, 8, and 9 (GND, RXD, TXD) of the I/O connector.

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**Note****Default Baud Rates**

The default baud rate is 9600 bps.

In bootloader mode, the baud rate is 115200 bps.

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**Info****USB to UART converter**

For example, the TTL-232R-5V from FTDI is working with the module and has been tested. More information on this converter is available on the FTDI website: [www.ftdichip.com](http://www.ftdichip.com)

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**NOTICE****5V TTL UART Level**

The TTL UART interface works with 5V level. Take special care when selecting a converter cable for USB connection.

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### 4.4 Status LEDs

The PD57/60-x-1076 has one green status LED. See figure 10 for its location.

| State        | Description                             |
|--------------|---|
| Blinking     | Heartbeat, MCU active, normal operation |
| Permanent on | Bootloader mode                         |
| Off          | Power Off                               |

Table 7: LED state description

## 5 Functional Description

### 5.1 Typical Application Wiring

Wire the PD57/60-x-1076 as shown in the following figures.

- Connect the power supply to V+ and GND.
- Connect the Step and Direction signals to your motion controller.
- At power up time, the EN input must be logically off (= driver stage disabled)!
- Optional: Connect UART to a TTL UART interface with 5V logic levels. To configure your PD57/60-x-1076 connect start the TMCL-IDE and use the parameterization tools. For detailed instructions refer to the PD57/60-x-1076-firmware-manual.

#### Note

**The TTL UART interface is not optically isolated. It requires 5V level signals.** Nevertheless, it provides basic ESD and rail-to-rail signal line protection for the PD57/60-x-1076.

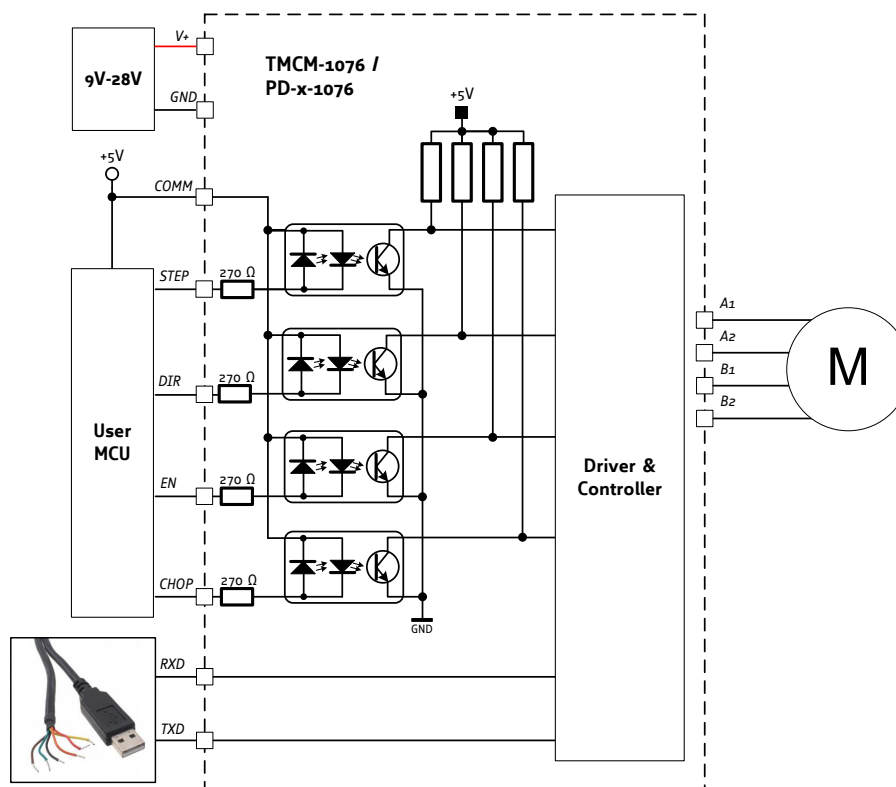


Figure 11: Typical application scenario with 5V inputs

### 5.2 Optically Isolated Inputs with Common Anode Input

The control inputs of the PD57/60-x-1076 are optically isolated (not the TTL UART interface). All optocouplers share one common anode (COMM) input as shown in the figure above.

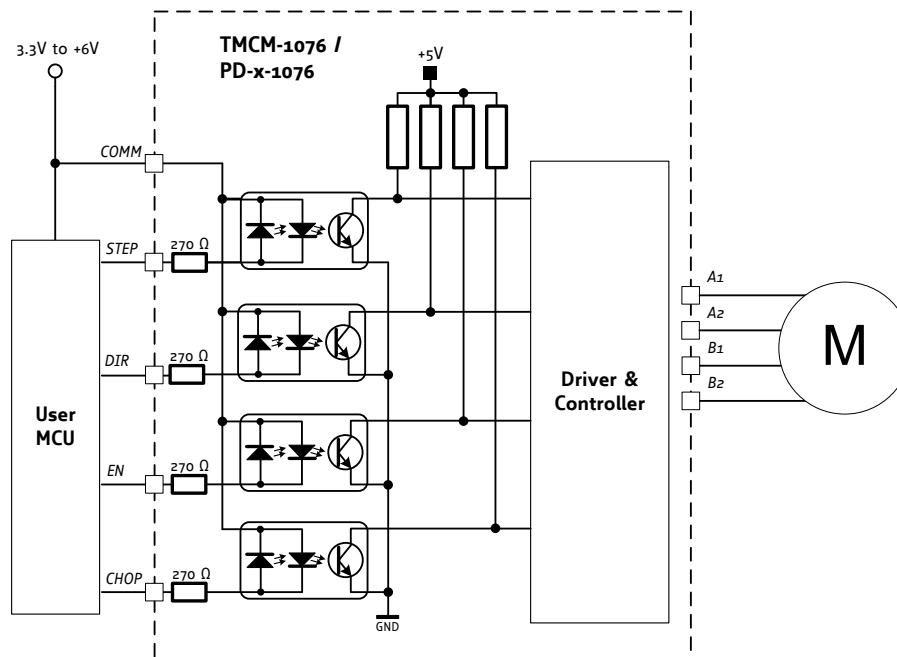


Figure 12: Inputs with common anode input with 3.3V to 5V

The typical voltage at COMM input is 5V. Nevertheless, 3.3V or voltages higher than 5V can also be used as long as the current through the optocouplers' emitter is between 5mA to 20mA. For 3.3V operation the controller must be carefully selected with respect to its I/O ports, its actual output voltage, and the series resistor of the I/O ports. The user must make sure that the current through the optocouplers' emitter is between 5mA to 20mA.

#### Note

##### Step pulse width

With the COMM input connected to ground, the width of the step pulses should be between  $2\mu\text{s}$  and  $4\mu\text{s}$ , for maximum step frequency.

With a larger step pulse width, for example 50% duty cycle coming from a frequency generator, the maximum input frequency will be lower at ca. 9kHz. With the COMM input connected to +5V, longer step pulses are necessary.

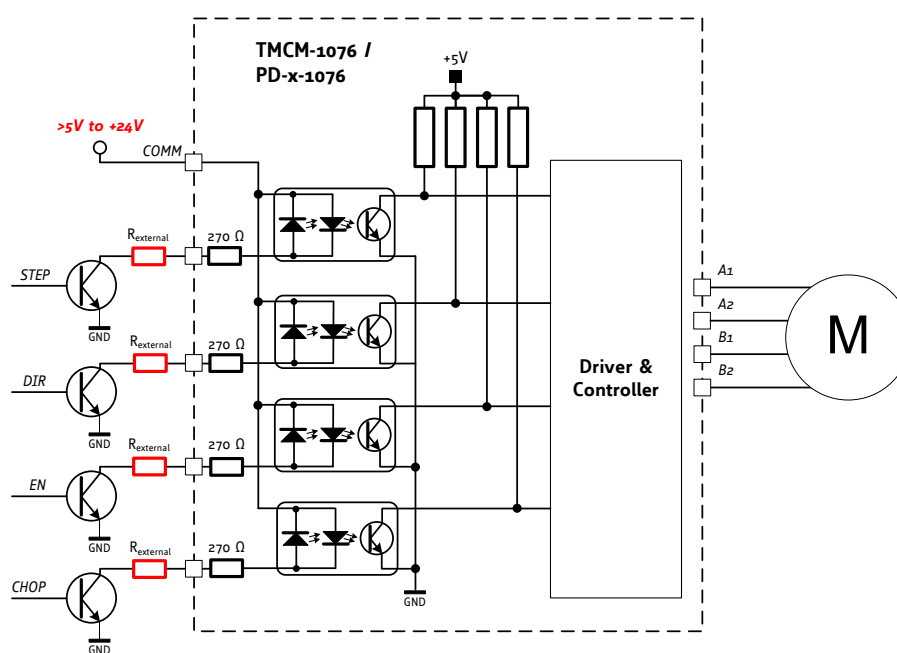


Figure 13: Inputs with common anode input with >5V to 24V

The series resistors in the PD57/60-x-1076 are 270mOhms. For operation with voltages higher than 5V an additional external resistor  $R_{external}$  is required per input to limit the current. See Table 8 as reference for additional external resistor values.

| COMM Voltage (V) | Value of $R_{external}$ ( $\Omega$ ) |
|------------------|--------------------------------------|
| 3.3              | -                                    |
| 5                | -                                    |
| 9                | 300                                  |
| 12               | 500                                  |
| 15               | 700                                  |
| 24               | 1K5                                  |

Table 8: Additional resistor reference values

#### Note

##### $R_{external}$ Selection

Take care when selecting an additional external resistor. The resistor type must have a fitting power rating. This depends on the voltage used at COMM input.

### 5.3 Optically Isolated Inputs with Common Cathode Input

The optocouplers inside PD57/60-x-1076 are bidirectional types (AC/DC). Thus, COMM can also be used as common cathode connection.



## 5.4 Input Logic

The logic of the optically isolated inputs depends on the usage of common anode input or common cathode input. The following table shows the logic of the CHOP input and the logic of the EN input.

|               | COMM=3.3...5V<br>(Common anode) | COMM=GND<br>(Common cathode) |
|---------------|---------------------------------|------------------------------|
| CHOP=GND      | SpreadCycle                     | StealthChop                  |
| CHOP=3.3...5V | StealthChop                     | SpreadCycle                  |
| EN=GND        | Motor enable                    | Motor disable                |
| EN=3.3...5V   | Motor disable                   | Motor enable                 |

## 5.5 Thermal Behavior

The default configuration parameters of the PD57/60-x-1076 are set to the specified maximum current of 3A RMS / 4.2A peak, which is the maximum motor phase current specified for the stepper motor options given in Table 4.

Typically, at this nominal current setting the stepper motor and the driver electronics will get hot. Continuous operation at maximum current is not guaranteed without cooling the motor since the stepper driver will switch off due to its internal over-temperature protection until temperature falls below the threshold.

### Note

#### Operation with Maximum Current Setting

For table-top testing and application bring-up the current should be reduced or the coolStep feature should be configured to keep heating on a reasonable level. Especially, when there is no other cooling option for the motor.

For proper and continuous operation at maximum current, the motor flange must be mounted to the applications mechanical interface with good contact.

## 6 Operational Ratings and Characteristics

### 6.1 Absolute Maximum Ratings

| Parameter                                  | Min | Max | Unit |
|--|-----|-----|------|
| Supply voltage                             | +10 | +30 | V    |
| Working temperature                        | -30 | +40 | ° C  |
| Motor coil current / sine wave <b>peak</b> |     | 4.2 | A    |
| Continuous motor current ( <b>RMS</b> )    |     | 3   | A    |

#### NOTICE

**Avoid exceeding the absolute maximum rating under all circumstances.** Stresses above those listed under "Absolute Maximum Ratings" may cause permanent damage to the device. This is a stress rating only and functional operation of the device at those or any other conditions above those indicated in the operation listings of this specification is not implied. Exposure to maximum rating conditions for extended periods may affect device reliability.

Keep the power supply voltage below the upper limit of +30V! Otherwise the board electronics will seriously be damaged! Especially, when the selected operating voltage is near the upper limit a regulated power supply is highly recommended.

### 6.2 Electrical Characteristics (Ambient Temperature 25° C)

| Parameter   | Symbol         | Min | Typ            | Max                  | Unit |
|---|----------------|-----|----------------|----------------------|------|
| Supply voltage  | $V_{DD}$       | 10  | 24             | 30                   | V    |
| Motor coil current / sine wave <b>peak</b> (chopper regulated, adjustable via TTL UART interface) | $I_{COILpeak}$ | 0   |                | 4.2                  | A    |
| Continuous motor current ( <b>RMS</b> )   | $I_{COILRMS}$  | 0   |                | 3                    | A    |
| Power supply current  | $I_{DD}$       |     | $\ll I_{COIL}$ | $1.4 \cdot I_{COIL}$ | A    |

Table 10: Electrical Characteristics

### 6.3 I/O Ratings (Ambient Temperature 25° C)

| Parameter                                  | Symbol        | Min  | Typ | Max        | Unit |
|--|---------------|------|-----|------------|------|
| COMM input voltage                         | $V_{COMM}$    | 3.3  | 5   | + $V_{DD}$ | V    |
| Input frequency of optically isolated I/Os | $f_{in}$      |      |     | 45         | kHz  |
| TTL UART input voltage                     | $V_{TTL\_IN}$ |      | 5   | 5.5        | V    |
| TTL UART low level voltage                 | $V_{TLL\_L}$  | 0    |     | 1.75       | V    |
| TTL UART high level voltage                | $V_{TTL\_H}$  | 3.25 |     | 5          | V    |

|                         |                |  |   |  |   |
|-------------------------|----------------|--|---|--|---|
| TTL UART output voltage | $V_{TTL\_OUT}$ |  | 5 |  | V |
|-------------------------|----------------|--|---|--|---|

Table 11: Operational ratings of optically isolated inputs and TTL UART interface

## 6.4 Functional Characteristics

| Parameter           | Description / Value  |
|---------------------|--|
| Control             | 4-wire interface with Step, Direction, Enable, and Chopper Mode Switch   |
| Step Pulse Width    | The step pulse width should be between $2\mu\text{s}$ and $4\mu\text{s}$ for maximum frequency. With a larger step pulse width, for example 50% duty cycle coming from a frequency generator, the maximum input frequency will be lower at ca. 9kHz. |
| Communication       | 2-wire TTL UART interface for configuration, 9600-115200 bps (default 9600 bps)  |
| Driving Mode        | spreadCycle and stealthChop chopper modes (selectable with CHOP input), adaptive automatic current reduction using stallGuard2 and coolStep  |
| Stepping Resolution | Full, 1/2, 1/4, 1/8, 1/16, 1/32, 1/64, 1/128, 1/256 step, default is 1/16 with internal interpolation to 1/256   |

Table 12: Functional Characteristics

## 6.5 Other Requirements

| Specifications      | Description or Value  |
|---------------------|---|
| Cooling             | Free air  |
| Working environment | Avoid dust, water, oil mist and corrosive gases, no condensation, no frosting |
| Working temperature | -30° C to +40° C  |

Table 13: Other Requirements and Characteristics

## 7 Abbreviations used in this Manual

| Abbreviation | Description                                 |
|--------------|---|
| COMM         | Common Anode or common cathode              |
| IDE          | Integrated Development Environment          |
| LED          | Light Emmitting Diode                       |
| RMS          | Root Mean Square value                      |
| TMCL         | TRINAMIC Motion Control Language            |
| TTL          | Transistor Transistor Logic                 |
| UART         | Universal Asynchronous Receiver Transmitter |
| USB          | Universal Serial Bus                        |

*Table 14: Abbreviations used in this Manual*

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## 10 Supplemental Directives

### 10.1 Producer Information

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## 11 Revision History

### 11.1 Hardware Revision

| Version | Date        | Author | Description   |
|---------|-------------|--------|---|
| 1.00    | 2018-FEB-28 | GE     | First prototype version.  |
| 1.10    | 2018-APR-09 | GE     | Pull-ups for opto-isolator changed to lower values (to be compatible with TMCM-1070). |

Table 15: Hardware Revision

### 11.2 Document Revision

| Version | Date        | Author | Description                              |
|---------|-------------|--------|--|
| 1.00    | 2018-MAR-26 | GE     | First release.                           |
| 1.01    | 2018-JUL-18 | SK     | Order codes fixed.                       |
| 1.02    | 2018-SEP-03 | GE     | Product photo updated.                   |
| 1.03    | 2019-AUG-01 | OK     | Document meta information added.         |
| 1.04    | 2021-JUN-03 | OK     | Notice about EN input corrected.         |
| 1.05    | 2021-SEP-03 | OK     | Notice about step pulse length extended. |
| 1.06    | 2021-SEP-24 | OK     | New block diagram.                       |
| 1.07    | 2022-JAN-07 | OK     | New section <a href="#">5.4</a> .        |

Table 16: Document Revision